

routing space and path and obstacles

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Pipe Routing= Path Planning (with Many Constraints)

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... The algorithm computing time **path** L,, of IL5 consists of ... Approximate the free **space** iii C as a coumservative ... ___ LE8 L Figure 1: Pipe **Routing** Examiple search ... <u>Cited by 8 - Related Articles - Web Search</u>

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Dynamic global path planning with uncertainty for mobile robots inmanufacturing

H Hu, M Brady - Robotics and Automation, IEEE Transactions on, 1997 - ieeexplore.ieee.org ... in such problems is to find the **route** between two ... **space**, and X is the state **space** (or nodes in ... say described by W . For a predefined **path**, unexpected **obstacles** ... <u>Cited by 16 - Related Articles - Web Search - BL Direct</u>

Path finding for human motion in virtual environments - group of 3 »

S Bandi, D Thalmann - Computational Geometry: Theory and Applications, 2000 - Elsevier ... obstacles. A collision free path is computed by searching the regions of configuration space free of configuration space obstacles. The ... Cited by 15 - Related Articles - Web Search

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MT Doreau, P Koziol - Proceedings of the 18th conference on Design automation, 1981 - portal.acm.org ... 3. Solution/Physical **Space** Relationship ... These are "conventional" **routing obstacles**. ... The task of the Drawer is to find a **path** through the scratchpad maze ... Cited by 8 - Related Articles - Web Search

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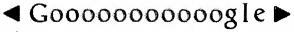
DT Lee, CD Yang, CK Wong - Discrete Applied Mathematics, 1996 - iis.sinica.edu.tw ... rst one nding a shortest path between two points on a routing plane with ... O (m 2) space to represent an mm ... O (12) for nding a path crossing I grid points. ... Cited by 28 - Related Articles - View as HTML - Web Search - BL Direct

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Optimal buffered routing path constructions for single and multiple clock domain systems - group of 10 »

S Hassoun, CJ Alpert, M Thiagarajan - Proceedings of the 2002 IEEE/ACM international conference on ..., 2002 - doi.ieeecomputersociety.org

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state-space. In the routing plane then, we have a starting point, s, to be connected to a ... cost of a path from 8 to a node n as (n). Notice that ... ieeexplore.ieee.org/iel5/10570/33447/01585771.pdf?arnumber=1585771 - Similar pages [More results from ieeexplore ieee.org]

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6 Mbps over direct path; 9 Mbps over two-hop path! •. Multihop benefit even greater in non-

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(PPT) Path Planning Part 1

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Place waypoints at every convex corner of the obstacles ... Now we are expanding nodes

according to best estimated total path cost. Is it optimal? ...

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of obstacles within the design can be identified and avoided dur- ... mate shapes which

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the segments of routed wires are regarded as obstacles for the rest of nets. ... If the

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routing space. This can be done using either the point-based. or the tile-based approach.

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